AMENDMENTS TO THE SPECIFICATION:

Please replace the paragraph beginning on page 9, line 8, with the following amended paragraph:

After the route is set, the vehicle starts traveling, and then the processor 12 starts the guide point image processing. In the guide point image processing, the processor 12 receives the data of the current position of the vehicle from the GPS device 13, as shown in FIG. 4 (step S11), and determines whether the distance from the current position to the next guide point on the route to the destination is within the first predetermined distance (e.g., 300 m) (step S12). Once the route to the destination is fixed, the data on the guide point on the route can be acquired from the road data, so that the judgment in step S12 is performed according to the data on the guide point. When the distance from the current position to the next guide point becomes the first predetermined distance or less, the image request, including information of the current position of the vehicle, heading direction and next ~~guild~~ guide point, is sent to the server 2 (step S13).

Please replace the paragraph beginning on page 12, line 13, with the following amended paragraph:

Also the processor 12 acquires the data of the current position and heading direction of the vehicle from the GPS device 13 (step S19), and determines whether the distance from the current position to the next guide point on the route to the destination is within the third predetermined distance (e.g., 20 m) (step S20). The third predetermined distance is shorter than the second predetermined distance. If the distance from the current position to the next guide point is the third predetermined distance or less, the image data on the current image in front of the vehicle is loaded from the camera 11 (step S21), and the current position and

heading direction of the vehicle and the next guide point are sent to the server 2 as the additional information, along with the image data (step S22). By this transmission of the image data to the server 2, guide point image processing for one guide point ends. If [[the]] a next guide point still exists before the destination, the guide point image processing is repeated for that guide point. It should be noted that the additional information may include information other than those mentioned above, such as the mounting position of the camera 11 on the vehicle. The image data need not be sent to the server for each guide point, but may be collectively sent later. Data may be loaded to a recording medium in a house and sent later from the house.

Please replace the paragraph beginning on page 16, line 11, with the following amended paragraph:

If the objects in the guide point have not changed, it is then determined whether the clarity of the image of the received image data is higher than the clarity of the image of the existing image data (step S49). Since information on the clarity ~~clarify~~ of the image is attached to the image data stored in the storage device 21, the image clarity of the existing image data is read and compared with the image clarity of the received image data for the judgment in step S49. If the clarity of the image of the received image data is higher than the clarity of the image of the existing image data, the identification degree of the guide point is added to the received image data, and the received image data is stored in the storage position of the storage device 21 which is determined depending on the image conditions (step S50). In step S50, just like the case of the changed target objects, the received image data is stored in this storage position, instead of the existing image data in the storage position read in step S47. If the clarity of the image of the received image data is not more than the clarity of the

image of the existing image data, the existing image data in the storage position read in step S47 remains in that storage position.